



Attorney Docket No. 392.1627

cfcc

IN THE UNITED STATES PATENT AND TRADEMARK OFFICE

In re Patent Application of:

Akihiro TERADA et al.

Application No.: 09/265,432

ATTENTION

Confirmation No.: 4506

CERTIFICATE OF CORRECTION

Filed: March 10, 1999

BRANCH

U.S. Patent No.: 7,092,791

Batch No.:

Issued: August 15, 2006

For: ROBOT SYSTEM AND MACHINING METHOD WITH ROBOT SYSTEM

REQUEST FOR CERTIFICATE OF CORRECTION

Commissioner for Patents
PO Box 1450
Alexandria, VA 22313-1450

Sir:

**Certificate
NOV 02 2006
of Correction**

Patentee(s) respectfully request(s) that a Certificate of Correction be issued in the subject patent, pursuant to 35 USC § 254 and 37 CFR § 1.322, to correct the error(s) shown on the attached Form PTO-1050. A check in the amount of \$100 to cover the cost of the Certificate is attached.

One or more of the errors shown on the attached Form PTO-1050 is or are within the responsibility of the undersigned; each thereof is of a clerical or typographical nature or of minor character and occurred in good faith, and the correction thereof is consistent with the prosecution record.

Respectfully submitted,

STAAS & HALSEY LLP

Date: 10-30-06

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UNITED STATES PATENT AND TRADEMARK OFFICE

CERTIFICATE OF CORRECTION

PATENT NO : 7,092,791

DATED : August 15, 2006

INVENTOR(S) : Akihiro TERADA et al.

It is certified that error appears in the above-identified patent and that said Letters Patent are hereby corrected as shown below:

First Page Column 2 (Abstract), Line 6, change "moveable" to --movable--.

First Page Column 2 (Abstract), Line 16, change "the" to --therefore--.

Column 4, Line 13, after "the" delete "a".

Column 5, Line 22, change "axis." to --axis--.

Column 6, Line 21, change "perpendicular." to --perpendicular to the first additional axis 12d and the machining nozzle 2 attached to a distal end of the second additional variable axis 12e in which a direction of irradiating laser beam is directed in a direction perpendicular to the additional rotational axis 12c (the final axis 1 of the movable arm of the robot).--.

Column 6, Line 30, change "12e.," to --12e--.

Column 6, Line 50, after "are" delete "is".

Column 7, Line 51, change "restriction-According" to --restriction. According--.

Column 7, Line 61, Change "lob" to --14b--.

Column 8, Line 19, after "the" insert --sixth--.

Column 10, Line 23, change $y = \left[\left[(R + r \cos \alpha)(R - r \cos \alpha) \right]^{1/2} - (R^2 - r^2)^{1/2} \right]$ to $y = \left[\left[(R + r \cos \alpha)(R - r \cos \alpha) \right]^{1/2} - (R^2 - r^2)^{1/2} \right]$ --.

Column 11, Line 64, change "an" to --can--.

Column 12, Line 34, change "moveable" to --movable--.

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